

## ABSTRACT

5 A method for machining workpieces by means of a multiaxial  
manipulator, such as an industrial robot, with a tool moved  
proportionally by a control unit of the manipulator and  
which can perform characteristic movements with several de-  
10 grees of freedom is characterized in that the degrees of  
freedom of the tool are evaluated together with the degrees  
of freedom of axes of the manipulator in real time for mov-  
ing a tool tip (TCP) in accordance with a predetermined,  
continuous machining path or a portionwise continuous ma-  
15 chining geometry (step function) and for determining a  
movement of the manipulator. The invention also proposes a  
device suitable for performing the aforementioned method,  
in which the tool and a tool tip, during workpiece machin-  
ing, are movement-controllable by the manipulator control  
unit. In this way it is possible to drastically reduce the  
20 overall machining time.

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